

QV
PCT

WORLD INTELLECTUAL PROPERTY ORGANIZATION
International Bureau



INTERNATIONAL APPLICATION PUBLISHED UNDER THE PATENT COOPERATION TREATY (PCT)

(51) International Patent Classification ⁶ : G05D 1/02	A1	(11) International Publication Number: WO 00/04430 (43) International Publication Date: 27 January 2000 (27.01.00)
(21) International Application Number: PCT/US99/16078 (22) International Filing Date: 16 July 1999 (16.07.99) (30) Priority Data: 98305761.3 20 July 1998 (20.07.98) EP (71) Applicant (for all designated States except US): THE PROCTER & GAMBLE COMPANY [US/US]; One Procter & Gamble Plaza, Cincinnati, OH 45202 (US). (72) Inventors; and (75) Inventors/Applicants (for US only): BOTTOMLEY, Ian [GB/GB]; 17 Howick Street, Alnwick, Northumberland NE66 1UZ (GB). COATES, David [GB/GB]; 14 Percy Road, Shilbottle, Northumberland NE66 2HF (GB). GRAYDON, Andrew, Russell [GB/GB]; 42 The Wills Building, Wills Oval, Newcastle-upon-Tyne NE7 7RW (GB). (74) Agents: REED, T., David et al.; The Procter & Gamble Company, 5299 Spring Grove Avenue, Cincinnati, OH 45217-1087 (US).		(81) Designated States: AE, AL, AM, AT, AT (Utility model), AU, AZ, BA, BB, BG, BR, BY, CA, CH, CN, CU, CZ, CZ (Utility model), DE, DE (Utility model), DK, DK (Utility model), EE, EE (Utility model), ES, FI, FI (Utility model), GB, GD, GE, GH, GM, HR, HU, ID, IL, IN, IS, JP, KE, KG, KP, KR, KZ, LC, LK, LR, LS, LT, LU, LV, MD, MG, MK, MN, MW, MX, NO, NZ, PL, PT, RO, RU, SD, SE, SG, SI, SK, SK (Utility model), SL, TJ, TM, TR, TT, UA, UG, US, UZ, VN, YU, ZA, ZW, ARIPO patent (GH, GM, KE, LS, MW, SD, SL, SZ, UG, ZW), Eurasian patent (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM), European patent (AT, BE, CH, CY, DE, DK, ES, FI, FR, GB, GR, IE, IT, LU, MC, NL, PT, SE), OAPI patent (BF, BJ, CF, CG, CI, CM, GA, GN, GW, ML, MR, NE, SN, TD, TG). Published <i>With international search report.</i>
(54) Title: ROBOTIC SYSTEM (57) Abstract <p>A self-propelled robot is disclosed for movement over a surface to be treated. The robot has a power supply (11) and a pair of wheels (8,9) driven by motors (6, 7) for moving the robot over the surface. A mechanism (113, 115, 16) is provided for controllably depositing a fluent material onto the surface. Navigation sensors (4, 13, 18, 21) provide signals for enabling the robot to navigate over the surface and one or more detectors (14, 15, 17) detect the presence of the material on the surface and provide signals indicative of its presence. A control system (100) receives the signals from the sensors and detectors and controls the motors and the depositing mechanism in dependence upon the signals received from the sensors and detectors.</p>		